

**AMENDMENTS TO THE CLAIMS**

1. (Currently Amended) A haptic~~Haptic~~ feedback apparatus comprising:  
a force applicator~~application means~~ arranged to apply a force to an elongate intervention device, the intervention device carrying at least one force sensor arranged to sense a remote force acting on the intervention device;  
a controller~~control means~~ arranged to control the force applied to the intervention device by the force applicator~~application means~~, the controller~~control means~~ being connected to the at least one force sensor arranged to sense a remote force on the intervention device and the control means being arranged to calculate the applied force in accordance based on with the remote force, the applied force being an amplification of the remote force,  
wherein the force applicator~~application means~~ comprises a resilient member arranged to apply the said force to the intervention device, and  
wherein the apparatus further comprises a sensor arranged to detect frictional force between the resilient member and the intervention device.
2. (Currently Amended) The Haptic~~Haptic~~ feedback apparatus according to claim 1, wherein the detected frictional force is used to control the~~an~~ amount of applied force.
3. (Currently Amended) The Haptic~~Haptic~~ feedback apparatus according to claim 1, further comprising a tracking device~~means~~ for tracking the rotational movement of the intervention device.
4. (Currently Amended) The Haptic~~Haptic~~ feedback apparatus according to claim 1, further comprising a tracking device~~means~~ for tracking the linear movement of the intervention device.
5. (Currently Amended) The Haptic~~Haptic~~ feedback apparatus according to claim 1, further comprising a comparator~~means~~ for comparing the remote force with a reference force.

6. (Currently Amended) ~~The Haptic~~haptic feedback apparatus according to claim 1, wherein the intervention device and the at least one force sensor ~~is~~are suitable for insertion into a simulated human model.

7. (Currently Amended) ~~The Haptic~~haptic feedback apparatus according to claim 6, wherein the remote force is generated using computer simulation.

8. (Currently Amended) ~~The Haptic~~haptic feedback apparatus according to claim 7, wherein the intervention device and the at least one force sensor ~~is~~are operable to be inserted into a human subject.

9. (Currently Amended) ~~The Haptic~~haptic feedback apparatus according to claim 8, wherein the at least one force sensor is disposed near or at a tip of the intervention device.

10. (Currently Amended) ~~The Haptic~~haptic feedback apparatus according to claim 7, further comprising a plurality of force sensors disposed along ~~the~~a length of the intervention device and the ~~control means~~controller is connected to each of the plurality of force sensors.

Claims 11-36 (Cancelled)

37. (New) The haptic feedback apparatus according to claim 9, wherein the at least one force sensor is embedded in the intervention device.

38. (New) The haptic feedback apparatus according to claim 10, wherein the plurality of force sensors are arranged to detect a shape of the intervention device.

39. (New) The haptic feedback apparatus according to claim 10, wherein the plurality of force sensors are embedded in the intervention device.